

AMENDMENTS TO THE CLAIMS:

Please replace the claims with the claims provided in the listing below wherein status, amendments, additions and cancellations are indicated.

1. - 8. (Cancelled)

9. (New) A control system for a floating mobile object, wherein,
the floating mobile object comprises:

a main body part that can be considered as a single rigid body
constituting a part of the thrust for the floating mobile object; and

an effector part for generating a thrust for the floating mobile
object; and

a thrust transfer gate for dynamically connecting the main
body part and the effector part, the thrust transfer gate being adapted to be able to
actually measure a thrust from the effector part acting on the main body part,

the main body part includes acceleration measurement means capable
of measuring an acceleration of the floating mobile object, and

a thrust command to the effector part is obtained by using:

an output from the acceleration measurement means of the
main body part; and

a measured thrust valve from the thrust transfer gate.

10. (New) A control system for a floating mobile object, wherein,
the floating mobile object comprises:

a main body part that can be considered as a single rigid body
constituting a part of the floating mobile object;

an effector part for generating a thrust for the floating mobile
object; and

a thrust transfer gate for dynamically connecting the main
body part and the effector part, the thrust transfer gate being adapted to be able to
actually measure a thrust from the effector part acting on the main body part,

the main body part is dynamically connected only to the thrust
transfer gate, the main body part being adapted to receive substantially all forces
acting thereon via the thrust transfer gate, and

a thrust command to the effector part is obtained by using a
measured thrust value from the thrust transfer gate.

11. (New) The control system for a floating mobile object according to
claim 9, wherein,

the thrust transfer gate includes force/torque measurement means capable of measuring a force/torque applied between the main body part and the effector part, and

the thrust command to the effector part is obtained by using:

an output from the force/torque measurement means of the floating mobile object; and

a target acceleration trajectory command obtained by converting an externally inputted target position/velocity trajectory command.

12. (New) The control system for a floating mobile object according to claim 10, wherein,

the thrust transfer gate includes force/torque measurement means capable of measuring a force/torque applied between the main body part and the effector part, and

the thrust command to the effector part is obtained by using:

an output from the force/torque measurement means of the thrust transfer gate; and

a target acceleration trajectory command obtained by converting an externally inputted target position/velocity trajectory command.

13. (New) A control system for a floating mobile object, wherein,
the floating mobile object includes acceleration measurement means
capable of measuring an acceleration of the floating mobile object,
the floating mobile object is arithmetically divided into:
a virtual main body part that can be considered as a single
rigid body constituting a part of the floating mobile object;
a virtual effector part for generating a thrust for the floating
mobile object; and
a virtual thrust transfer gate for virtually connecting the
virtual main body part and the virtual effector part, the virtual thrust transfer gate
being adapted to be able to estimate a thrust from the virtual effector part acting on
the virtual main body part based on an output from the acceleration measurement
means, and
a thrust command to the virtual effector part is obtained by using an
estimated thrust value from the virtual thrust transfer gate.

14. (New) The control system for a floating mobile object according to
claim 13, wherein,

the virtual thrust transfer gate includes force/torque estimation means capable of estimating a force/torque applied between the virtual main body part and the virtual effector part, and

the thrust command to the virtual effector part s obtained by using:

an output from the force/torque estimation means of the virtual thrust transfer gate; and

a target acceleration trajectory command obtained by converting an externally inputted target position/velocity trajectory command.

15. (New) The control system for a floating mobile object according to any one of claims 9 through 14, wherein,

the main body part or the virtual main body part additionally includes inclination angle measurement means capable of measuring an inclination of the floating mobile object, and

the thrust command to the effector part or the virtual effector part is obtained by additionally using an output from the inclination angle measurement means.

16. (New) The control system for a floating mobile object according to any one of claim 9 through 14, wherein,

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the floating mobile object additionally includes position/velocity measurement means capable of measuring a position or a velocity of the floating mobile object, and

the thrust command to the effector part or the virtual effector part is obtained by additionally using an output from the position/velocity measurement means and an externally inputted target position command or target velocity command.